

AMENDMENTS TO THE SPECIFICATION

Please amend the paragraph beginning on page 1, line 10 as follows:

An industrial robot is commonly used in the industry. Fig. 10 illustrates a schematic industrial robot 100 comprising a controller 101 including a calculator 102, manipulator 103 and a robot controller. As an example for origin adjustment in a conventional industrial robot, Japanese Patent Unexamined Publication No. H02-180580 (document 1) discloses the following device. Fig. 8 illustrates a conventional origin adjusting device.

At page 5, line 5, please insert the following new paragraph:

Fig. 10 illustrates a schematic industrial robot.

Please delete the paragraph beginning on page 5, line 6 (beginning with “REFERENCE MARKS”) and ending on page 6, line 1 (ending with “95 Attaching Part”).

Please amend the paragraph beginning on page 6, line 7 as follows:

Figs. 1 and 2 illustrate the portion of the origin adjusting device of a joint of an industrial robot according to the exemplary embodiment of the present invention. The origin adjusting device according to the embodiment has first member 11 and second member 12. Second member 12 is rotated, for example, by a driving motor 13. First member 11 has positioning member 22; attaching part 23 embedding positioning member 22 therein; and guide 24 allowing positioning member 22 to slide. Guide 24 is a first hole formed at first member 11. Positioning member 22 is allowed to partially project from the first hole. Meanwhile, second member 12 has contacting part 21, which is a projection interacting with (i.e. contacting) positioning member 22, when relatively rotating first member 11 and second member 12. Here, positioning member 22 and the first hole (guide 24) through which positioning member 22 slides form socket and spigot structure, which is free from mechanical backlash. Contacting part 21 is included in an interacting means. Positioning member 22 provided on first member 11, attaching part 23, and guide 24 correspond to first positioning member 22, first attaching part 23, and first guide 24, respectively.

Please amend the paragraph beginning on page 8, line 9 as follows:

The next step for origin adjustment is shown in Fig. 2. Positioning member 22 is made to interact with contacting part 21 by relatively rotating first member 11 and second member 12 in a state of positioning member 22 projecting.